

**NEW CLAIMS**

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1. Method for determining the yaw angle of a satellite,

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wherein a fixed cartesian coordinate system is defined with regard to the satellite, having a first axis which is directed substantially tangential to the orbit of the satellite and defines a roll angle, having a second axis which is directed substantially perpendicular to the orbit plane of the satellite and defines a pitch angle, and having a third axis which is directed substantially radial to the orbit of the satellite and defines a yaw angle,

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comprising the steps of:

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providing a first angle sensor and a second angle sensor having different reference points and measuring the same angle about a measurement axis which is anti-parallel to the third axis,

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evaluating a first angle and a second angle about the measurement axis on the basis of the angle sensors, and

determining the yaw angle on the basis of the first angle and the second angle.

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2. Method according to claim 1, wherein the measurement axis is the first axis.

3. Method according to claim 1, wherein the measurement axis is the second axis.

4. Method according to claim 3, wherein

the satellite is a geo-stationary satellite, wherein the first angle sensor has its reference point at the center of earth (N) and the second angle sensor has its reference point at a ground station (G) located apart from the center of earth.

5. Method for determining the yaw angle of a satellite,

wherein a fixed cartesian coordinate system is defined with regard to the satellite, having a first axis which is directed substantially tangential to the orbit of the satellite and defines a roll angle, having a second axis which is directed substantially perpendicular to the orbit plane of the satellite and defines a pitch angle, and having a third axis which is directed substantially radial to the orbit of the satellite and defines a yaw angle,

comprising the steps of:

providing a first angle sensor and a set of angle sensors including a second and third angle sensor, wherein the first, second and third angle sensors measure angles about different measurement axes which are anti-parallel to the third axis and wherein for the first angle sensor and for the set of angle sensors different reference points are assigned,

evaluating measurement angles on the basis of the angle sensors, and

determining the yaw angle on the basis of the measurement angles.

- 5 6. Method according to claim 5, wherein the set of angle sensors comprises a first roll angle sensor (R1) and a first pitch angle sensor (P1) both related to a first reference point (G), and wherein the first angle sensor comprises a second roll angle sensor (R2) or a second
- 10 pitch angle sensor (P2), related to a second reference point (N) which is different from the first reference point (G).
7. Method according to claim 6, wherein for the first
- 15 sensor calculations are based on equations representable by the following expression:

$$20 \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(RM1) & -\sin(RM1) \\ 0 & \sin(RM1) & \cos(RM1) \end{bmatrix} \begin{bmatrix} \cos(PM1) & 0 & \sin(PM1) \\ 0 & 1 & 0 \\ -\sin(PM1) & 0 & \cos(PM1) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} =$$

$$\begin{bmatrix} \cos(Y) & -\sin(Y) & 0 \\ \sin(Y) & \cos(Y) & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(R) & -\sin(R) \\ 0 & \sin(R) & \cos(R) \end{bmatrix} \begin{bmatrix} \cos(P) & 0 & \sin(P) \\ 0 & 1 & 0 \\ -\sin(P) & 0 & \cos(P) \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(RR1) & -\sin(RR1) \\ 0 & \sin(RR1) & \cos(RR1) \end{bmatrix} \begin{bmatrix} \cos(PR1) & 0 & \sin(PR1) \\ 0 & 1 & 0 \\ -\sin(PR1) & 0 & \cos(PR1) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}$$

- 25 and wherein for the second sensor calculations are based on equations representable by the following expression:

$$\begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(RM2) & -\sin(RM2) \\ 0 & \sin(RM2) & \cos(RM2) \end{bmatrix} \begin{bmatrix} \cos(PM2) & 0 & \sin(PM2) \\ 0 & 1 & 0 \\ -\sin(PM2) & 0 & \cos(PM2) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} =$$

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$$\begin{bmatrix} \cos(Y) & -\sin(Y) & 0 \\ \sin(Y) & \cos(Y) & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(R) & -\sin(R) \\ 0 & \sin(R) & \cos(R) \end{bmatrix} \begin{bmatrix} \cos(P) & 0 & \sin(P) \\ 0 & 1 & 0 \\ -\sin(P) & 0 & \cos(P) \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(RR2) & -\sin(RR2) \\ 0 & \sin(RR2) & \cos(RR2) \end{bmatrix} \begin{bmatrix} \cos(PR2) & 0 & \sin(PR2) \\ 0 & 1 & 0 \\ -\sin(PR2) & 0 & \cos(PR2) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}$$

with

P, R, Y                   pitch, roll yaw angle errors,  
 RRx, PRx               roll and pitch angles of the sensor's  
                           reference point, and  
 5     RMx, PMx            measured roll and pitch angles (from  
                           center of a star or from the center of  
                           earth),

wherein one of the measurements RMx or PMx could be  
 10     unknown.

8.     Method according to claim 7, wherein the  
        first and the second reference points (G, N) are on the  
        earth.

15     9.     Method according to claim 8, wherein the  
        first and/or second reference points (G, N) are on a  
        star.

20     10.    Method according to claim 9, wherein the  
        satellite is a geo-stationary satellite.

11.    Method according to claim 5, wherein the attitude of the  
        satellite is determined by using the determined yaw angle.

25     12.    Method for determining a calibrated value for a yaw  
        angle of a satellite,

comprising the steps of:

30     storing a yaw angle profile over a quiet orbit,

determining a sample yaw angle at a calibration time  
        (t0),

determining a calibrated value by subtracting the sample yaw angle with a yaw angle profile value having a time shift in the yaw angle profile corresponding to the calibration time ( $t_0$ ).

13. Method for determining a calibrated value for a yaw angle of a satellite,

storing for each angle sensor on board of the satellite a profile over a quiet orbit,

determining a sample value for each of the angle sensors at a calibration time ( $t_0$ ),

determining calibrated values for each angle sensor by subtracting the sample values with a angle sensor profile value having a time shift in the respective angle sensor profile corresponding to the calibration time ( $t_0$ ),

determining a calibrated value for a yaw angle with calibrated values for each angle sensor.

14. Apparatus for determining the yaw angle of a satellite,

wherein a fixed cartesian coordinate system is defined with regard to the satellite, having a first axis which is directed substantially tangential to the orbit of the satellite and defines a roll angle, having a second axis which is directed substantially perpendicular to the orbit plane of the satellite and defines a pitch angle, and having a third axis which is directed substantially

radial to the orbit of the satellite and defines a yaw angle,

comprising:

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a first angle sensor and a second angle sensor having different reference points,

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means for measuring the same angle about a measurement axis which is anti-parallel to the third axis,

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means for evaluating a first angle and a second angle about the measurement axis on the basis of the angle sensors, and

means for determining the yaw angle on the basis of the first angle and the second angle.

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15. Apparatus according to claim 14, wherein the measurement axis is the first axis.

16. Apparatus according to claim 14, wherein the measurement axis is the second axis.

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17. Apparatus according to claim 16, wherein the satellite is a geo-stationary satellite, wherein the first angle sensor has its reference point at the center of earth (N) and the second angle sensor has its reference point at a ground station (G) located apart from the center of earth.

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18. Apparatus for determining the yaw of a satellite,

wherein a fixed cartesian coordinate system is defined with regard to the satellite, having a first axis which is directed substantially tangential to the orbit of the satellite and defines a roll angle, having a second axis which is directed substantially perpendicular to the orbit plane of the satellite and defines a pitch angle, and having a third axis which is directed substantially radial to the orbit of the satellite and defines a yaw angle,

comprising:

a first angle sensor and a set of angle sensors including a second and third angle sensor,

means for measuring by the first, second and third angle sensors angles about different measurement axes which are anti-parallel to the third axis, wherein for the first angle sensor and for the set of angle sensors different reference points are assigned,

means for evaluating measurement angles on the basis of the angle sensors, and

means for determining the yaw angle on the basis of the measurement angles.

19. Apparatus according to claim 18, wherein the set of angle sensors comprises a first roll angle sensor (R1) and a first pitch angle sensor (P1) both related to a first reference point (G), and wherein the first angle sensor comprises a second roll angle sensor (R2) or a second pitch angle sensor (P2), related to a second

reference point (N) which is different from the first reference point (G).

20. Apparatus according to claim 19, wherein for the first sensor calculations are based on equations representable by the following expression:

$$\begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(RM1) & -\sin(RM1) \\ 0 & \sin(RM1) & \cos(RM1) \end{bmatrix} \begin{bmatrix} \cos(PM1) & 0 & \sin(PM1) \\ 0 & 1 & 0 \\ -\sin(PM1) & 0 & \cos(PM1) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} =$$

$$\begin{bmatrix} \cos(Y) & -\sin(Y) & 0 \\ \sin(Y) & \cos(Y) & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(R) & -\sin(R) \\ 0 & \sin(R) & \cos(R) \end{bmatrix} \begin{bmatrix} \cos(P) & 0 & \sin(P) \\ 0 & 1 & 0 \\ -\sin(P) & 0 & \cos(P) \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(RR1) & -\sin(RR1) \\ 0 & \sin(RR1) & \cos(RR1) \end{bmatrix} \begin{bmatrix} \cos(PR1) & 0 & \sin(PR1) \\ 0 & 1 & 0 \\ -\sin(PR1) & 0 & \cos(PR1) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}$$

- 15 and wherein for the second sensor calculations are based on equations representable by the following expression:

$$\begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(RM2) & -\sin(RM2) \\ 0 & \sin(RM2) & \cos(RM2) \end{bmatrix} \begin{bmatrix} \cos(PM2) & 0 & \sin(PM2) \\ 0 & 1 & 0 \\ -\sin(PM2) & 0 & \cos(PM2) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} =$$

$$\begin{bmatrix} \cos(Y) & -\sin(Y) & 0 \\ \sin(Y) & \cos(Y) & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(R) & -\sin(R) \\ 0 & \sin(R) & \cos(R) \end{bmatrix} \begin{bmatrix} \cos(P) & 0 & \sin(P) \\ 0 & 1 & 0 \\ -\sin(P) & 0 & \cos(P) \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 \\ 0 & \cos(RR2) & -\sin(RR2) \\ 0 & \sin(RR2) & \cos(RR2) \end{bmatrix} \begin{bmatrix} \cos(PR2) & 0 & \sin(PR2) \\ 0 & 1 & 0 \\ -\sin(PR2) & 0 & \cos(PR2) \end{bmatrix} \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix}$$

- 25 with

P, R, Y                      pitch, roll yaw angle errors,  
 RRx, PRx                    roll and pitch angles of the sensor's  
                                  reference point, and  
 RMx, PMx                    measured roll and pitch angles (from  
 30 center of a star or from the center of  
                                  earth),

wherein one of the measurements RMx or PMx could be unknown.



21. Apparatus according to claim 20, wherein  
the first and the second reference points (G, N) are on  
the earth.

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22. Apparatus according to claim 21, wherein  
the first and/or second reference points (G, N) are on a  
star.

10 23. Apparatus according to claim 21, wherein  
the satellite is a geo-stationary satellite.

24. Apparatus according to claim 23, wherein  
comprising means for determining the attitude of a  
15 satellite.

25. Apparatus for determining a calibrated value for a yaw  
angle of a satellite,

20 comprising:

means for storing a yaw angle profile over a quiet  
orbit,

25 means for determining a sample yaw angle at a  
calibration time ( $t_0$ ),

30 means for determining a calibrated value by subtracting  
the sample yaw angle with a yaw angle profile value  
having a time shift in the yaw angle profile  
corresponding to the calibration time ( $t_0$ ).

26. Apparatus for determining a calibrated value for a yaw  
angle of a satellite,

means for storing for each angle sensor on board of the satellite a profile over a quiet orbit,

5 means for determining a sample value for each of the angle sensors at a calibration time ( $t_0$ ),

10 means for determining calibrated values for each angle sensor by subtracting the sample values with a angle sensor profile value having a time shift in the respective angle sensor profile corresponding to the calibration time ( $t_0$ ),

15 means for determining a calibrated value for a yaw angle with calibrated values for each angle sensor.